

ABSTRACT OF THE DISCLOSURE

In steering control for individually controlling wheel steering angles α_1 , α_2 , α_3 , and α_4 of a vehicle in accordance with a condition equation for forming a prescribed mode, one of the condition equation variables is used as a steering command value S . In a process for changing the command value S from a value S_1 to a value S_2 , for transitioning the steering angles α_1 , α_2 , α_3 , α_4 from values $[\alpha_1, \alpha_2, \alpha_3, \alpha_4]_{S1}$ corresponding to the steering command value S_1 , to values $[\alpha_1, \alpha_2, \alpha_3, \alpha_4]_{S2}$ corresponding to the steering command value S_2 , the steering angles α_1 , α_2 , α_3 , α_4 are changed toward incremental transition steering angles $[\alpha_1, \alpha_2, \alpha_3, \alpha_4]_{S1 + \Delta S}$ corresponding to a steering command value $(S_1 + \Delta S)$, which is the steering command value S_1 to which an incremental steering command value ΔS has been added. After the steering angles α_1 , α_2 , α_3 , α_4 reach their incremental transition steering angles and steering angle conformance is detected, the angles are changed toward incremental transition steering angles $[\alpha_1, \alpha_2, \alpha_3, \alpha_4]_{S1 + n\Delta S}$ corresponding to a steering command value $(S_1 + n\Delta S)$, which is the steering command value to which an incremental steering command value ΔS has been added [n times] in succession. [This is repeated as many times as required] to change the steering angles α_1 , α_2 , α_3 , α_4 from $[\alpha_1, \alpha_2, \alpha_3, \alpha_4]_{S1}$ to $[\alpha_1, \alpha_2, \alpha_3, \alpha_4]_{S2}$.